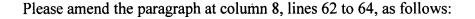
Please amend the paragraph at column 4, lines 58 to 63, as follows:

The status transition preparation portion 140 sets the states passed through from the state at the start of the operation of the robot 1 (starting state) to the state at the end of the operation (target state) and prepares a status transition chart (FIG. 4 etc.) as an operational state model based on the set states and the operational arcs at the time of transition between states. --



When the value v of the <u>uniform</u> [unifoorm] random number is in the range of $s_k \le v < e_k$, the operational arc A^k_{ij} corresponding to the value v of the uniform random number is selected. --

Please amend the paragraph at column 9, lines 31 to 35, as follows:

-- FIG. 9 is a view of the operational arcs <u>determined</u> [determined] by the status transition preparation portion 140, path selection portion 142, arc selection portion 144, and data transmission portion 146 based on the status transition chart shown in FIG. 8. --

Please amend the paragraph at column 9, lines 41 to 46, as follows:

However, when the starting state S_S and the target state S_G match, the series of <u>self</u> operational arcs A^k_{GG} is produced. At this time, the operating data corresponding to the series of



operational arcs A^k_{GG} is not supplied to the drive portions 120a to 120d. In this case, the state is not particularly changed and therefore useless processing can be eliminated. --

Please amend the paragraph at column 10, lines 42 to 45, as follows:

-- Further, according to the methods and apparatus for control of a robot of the present invention, it is possible to increase the number of <u>matters</u> [matter] expressable by the operations of the robot. --

IN THE CLAIMS:

Please amend claims 3 to 5 as follows:

- 3. (Amended) A robot control method as set forth in claim 1, wherein said [operational arc includes a] self operational arc shows [showing] the operation of said robot when returning from one state among the plurality of states to the same one state.
- 4. (Amended) A robot control apparatus for controlling the operation of a robot having a plurality of states corresponding to a predetermined operation,
- at least one operational arc being determined between each of any two directly passable states among said plurality of states showing the operation of the robot when passing between said two states, comprising a weighting means for giving to each of the

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